Abstract

A method and a device are described for determining a
future travel-path area of a first vehicle (700), which
is furnished with a distance sensor. In this context,
using the distance sensor at preestablished or selectable
time points, at least relative positions (707, 708) are
determined of at least one vehicle traveling ahead (702,
703) with respect to the first vehicle (700). At least
these determined relative positions (707, 708) are stored
in at least one storage device. These relative positions
(707, 708), stored in the storage device, constitute in
each case a course path (709, 710) of the corresponding
vehicle traveling ahead (702, 703). The future travel-
path area of the first vehicle (700) is determined at
least on the basis of the course path (709, 710) of the
vehicle traveling ahead (702, 703). The course path (709,
710) of the vehicle traveling ahead (702, 703) is
projected in the direction of the position of the first
vehicle (700).

(Figure 7)

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